



## Errata to “Multivalued Robust Tracking Control of Lagrange Systems: Continuous and Discrete-Time Algorithms” [Sep 17 4436-4450]

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# Comments on “Multivalued robust tracking control of Lagrange systems: Continuous and discrete-time algorithms”

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**Abstract**—Unfortunate mistakes in the statements of Theorems 1 and 6 in the above paper are corrected.

The first point of [1, Theorem 1] should read

1)  $\sigma$  is continuous and  $\dot{\sigma}$  is essentially bounded on bounded sets.

The sentence before (62) in [1, Theorem 6] should be replaced by

Then, we can find a subsequence of sampling times  $h$  converging to zero such that  $(\sigma_h, \tilde{q}_h)$  converges to  $(\sigma, \tilde{q})$ , where  $(\sigma, \tilde{q})$  is a solution of

## REFERENCES

- [1] F. Miranda, B. Brogliato, and F. Castaños, “Multivalued robust tracking control of Lagrange systems: Continuous and discrete-time algorithms,” *IEEE Trans. Autom. Control*, vol. 62, pp. 4436 – 4450, Sep. 2017.

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